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FUEL INJECTION QUANTITY CONTROL DEVICE

"EXPRESS MAIL" MAILING LABEL

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Cross Reference to Related Application

[0001] Applicants hereby claims foreign priority benefits under U.S.C § 119 of Japanese Patent Application No. 2003-8495, filed on January 16, 2003, and the content of which is herein incorporated by reference.

BACKGROUND OF THE INVENTION

1. Field of the Invention

[0002] The present invention relates to a fuel injection quantity control device which is capable of suppressing overshoot and undershoot when the actual revolution speed of an engine is controlled to the target revolution speed.

2. Description of the Related Art

[0003] When the actual revolution speed (rpm) of an engine is controlled to the target revolution speed (rpm), the control is conducted so as to increase or decrease the fuel injection quantity. The inventors are presently developing the following procedure for computing the fuel injection quantity.

[0004] This procedure comprises the steps of finding a difference e by subtracting the actual revolution speed from the target revolution speed, finding the proportional term output value ($Q_p = K_p \cdot e$) by multiplying the difference e by the prescribed proportionality constant K_p , finding the integral term output value ($Q_i = \int (K_i \cdot e) dt$) by integrating the product of difference e and the prescribed integration constant K_i , and obtaining the final injection quantity by adding up those proportional term output value Q_p and integral term output value Q_i . With this procedure, because not only the proportional term output value Q_p but also the integral term output value Q_i is used, the speed response is good.

[0005] Japanese Patent Application Laid-open No. H4-134155 is known as a reference relating to pertinent conventional technology.

[0006] However, with the above-described procedure, for example, when the actual revolution speed is brought up to the target revolution speed, that is when the difference is positive, the difference is continued to be added up in the process for computing the integral term output value till the difference between the two speeds becomes 0. Therefore, in the point of time at which the difference becomes 0, the fuel injection quantity can become too large causing overshoot (the actual revolution speed is above the target revolution speed).

[0007] Conversely, when the actual revolution speed is brought down to the target revolution speed, that is, when the difference is negative, the difference is continued to be subtracted in the process for computing the integral term output value till the difference between the two speeds becomes 0. Therefore, in the point of time at which the difference becomes 0, the fuel injection quantity can become too small causing undershoot (the actual revolution speed is less than the target revolution speed).

SUMMARY OF THE INVENTION

[0008] It is an object of the present invention, which was created with the foregoing in view, to provide a fuel injection quantity control device which is capable of suppressing overshoot and undershoot when the actual revolution speed of an engine is controlled to the target revolution speed.

[0009] In order to attain the above-described object, the present invention provides a fuel injection quantity control device for controlling an actual revolution speed of the engine to a target revolution speed, comprising: difference computation means for subtracting the actual revolution speed from the target revolution speed and finding the difference therebetween; proportional term computation means for multiplying the aforesaid difference by the prescribed proportionality constant and finding a proportional term output value; integral term computation means for finding an integral term output value which is obtained by integrating the product of the aforesaid difference and the prescribed integration constant; differential term

computation means for finding a differential term output value which is obtained by multiplying the value obtained by differentiating the aforesaid difference by the prescribed differentiation constant; and injection quantity computation means for adding up the aforesaid proportional term output value and integral term output value and determining the injection quantity, wherein the device further comprises correction means for limiting the lower limit of the integral term output value with the differential term output value when the aforesaid difference is negative, thereby suppressing the excess reduction of the injection quantity, and limiting the upper limit of the integral term output value with the differential term output value when the difference is positive, thereby suppressing the excess increase of the injection quantity.

[0010] With the fuel injection quantity control device in accordance with the present invention, when the actual revolution speed of the engine is controlled to the target revolution speed, overshoot and undershoot can be suppressed. Thus, limiting the lower limit of the integral term output value Q_i with the differential term output value Q_d suppresses undershoot, and limiting the upper limit of the integral term output value Q_i with the differential term output value Q_d suppresses overshoot.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1 is an explanatory drawing illustrating schematically the fuel injection quantity control device of an embodiment of the present invention;

FIG. 2 is an explanatory drawing illustrating difference computation means;

FIG. 3 is an explanatory drawing illustrating proportional term computation means;

FIG. 4 is an explanatory drawing illustrating integral term computation means;

FIG. 5 is an explanatory drawing illustrating differential term computation means;

FIG. 6 is an explanatory drawing illustrating fluctuations of actual revolution speed caused by fluctuations of integral term output value (when revolution speed is decreased); and

FIG. 7 is an explanatory drawing illustrating fluctuations of actual revolution speed caused by fluctuations of integral term output value (when revolution speed is increased).

DESCRIPTION OF THE PREFERRED EMBODIMENTS

[0011] The preferred embodiments of the present invention will be described hereinbelow with reference to the appended drawings.

[0012] The fuel injection quantity control device of the present embodiment controls the actual revolution speed E_n of an engine (diesel engine or the like) to the target revolution speed E_o and is used, for example, for revolution speed matching of semiautomatic transmissions in which manual shifting is made by mechanical operations or fully automatic transmissions and for idling control.

[0013] As shown in FIG. 1, this fuel injection quantity control device comprises injection quantity computation means 6 for adding up the below-described proportional term output value Q_p and integral term output value Q_i , implementing the lower limit limitation of a zero injection quantity and the upper limit limitation of a maximum limit injection quantity Q_m with respect thereto, and obtaining a final injection quantity Q . Thus, this injection quantity control device is based on proportional integral control (PI control).

[0014] The fuel injection quantity control device, as shown in FIG. 2, comprises difference computation means 1 for subtracting the actual revolution speed E_n from the target revolution speed E_o and finding the difference e . The target revolution speed E_o is set to a revolution speed (rpm) appropriately set by a computer during the above-mentioned revolution speed matching of a transmission or to an idling revolution speed (rpm). Furthermore, the actual revolution speed E_n is obtained with a rotation sensor which measures the revolution speed (rpm) of a crankshaft.

[0015] The fuel injection quantity control device, as shown in FIG. 3, comprises proportional term computation means 2 for multiplying the difference e by the prescribed proportionality constant K_p and finding a proportional term output value Q_p ($Q_p = K_p \cdot e$). The proportionality constant K_p is determined based on a map M1 from the difference e and a water temperature T . The water temperature T is obtained with a water temperature sensor which measures the temperature of cooling water.

[0016] The fuel injection quantity control device, as shown in FIG. 4, comprises integral term computation means 3 for finding an integral term output value Q_i which is obtained by integrating the product of the difference e and the prescribed integration constant K_i ($Q_i = \int (K_i \cdot e) dt$). The integration constant K_i is determined based on a map M2 from the difference e and water temperature T . The maximum and minimum values of the integral term output value Q_i are limited by the below-described correction means 4.

[0017] The fuel injection quantity control device, as shown in FIG. 5, comprises differential term computation means 5 for finding a differential term output value Q_d which is obtained by multiplying the value obtained by differentiating the difference e by the prescribed differentiation constant K_d ($Q_d = d/dt(K_d \cdot e)$). The differentiation constant K_d is computed by inputting the difference e into coefficient computation means Ca1, and the differential value of the difference e is computed by inputting an incremental revolution speed Δrpm into a filter Fil. The differential term output value Q_d is then found by multiplying the computed values.

[0018] Correction means 4, as shown in FIG. 4, limits the lower limit of the integral term output value Q_i with the differential term output value Q_d when the difference e is negative, thereby suppressing the excess decrease in the injection quantity, and limits the upper limit of the differential term output value Q_i with the differential term output value Q_d when the difference e is positive, thereby suppressing the excess increase in the injection quantity.

[0019] Thus, integral term computation means 3 and correction means 4, first, find an addition value Q_{i2} by adding up an output value Q_{i1} obtained by

multiplying the difference e by the prescribed integration constant K_i and the previous integral term output value Q_{i-1} . The lower limit of the addition value Q_{i2} is then limited by a larger (lower limit value Q_y) of the differential term output value Q_d and 0 and the excess decrease in the injection quantity is suppressed. As a result, undershoot is prevented.

[0020] More specifically, correction means 4 comprises a selection unit 44 for selecting the larger of the differential term output value Q_d and 0 and a lower limit limiter 45 for limiting the lower limit of the integral term output value Q_i with the lower limit value Q_y outputted from the selection unit 44. As a result, when the addition value Q_{i2} is less than the lower limit value Q_y , the lower limit value Q_y is outputted and it becomes a new integral term output value Q_i . As a result, undershoot is prevented.

[0021] Then, integral term computation means 3 and correction means 4 find the addition value Q_{i2} by adding up the output value Q_{i1} obtained by multiplying the difference e by the prescribed integration constant K_i and the previous integral term output value Q_{i-1} and then limit the upper limit of the addition value Q_{i2} to a value (upper limit value Q_x) obtained by adding a maximum limiting injection quantity Q_m to a smaller of the differential term output value Q_d or 0 and suppress the excess increase in the injection quantity. As a result, overshoot is prevented.

[0022] More specifically, correction means 4 comprises a selection unit 41 for selecting the smaller of the differential term output value Q_d or 0, an addition unit 42 for adding the maximum limiting injection quantity Q_m to the output value of the selection unit 41, and an upper limit limiter 43 for limiting the upper limit of the integral term output value Q_i with the upper limit value Q_x outputted from the addition unit 42. As a result, when the addition value Q_{i2} is larger than the upper limit value Q_x , the upper limit value Q_x is outputted and it becomes a new integral term output value Q_i . As a result, overshoot is prevented.

[0023] Correction means 4 operates (controls the upper limit or lower limit of the addition value Q_{i2}) when the engine and drive system are disconnected and the actual revolution speed E_n approaches the target revolution speed E_o within the prescribed value (for example, about 300-400 rpm). This is because if the upper

limit or lower limit control with correction means 4 is conducted at all times, a good speed response inherent to the proportional integral control is impeded.

[0024] Correction means 4 terminates operation (control of the upper limit or lower limit of the addition value Q_{i2}) and is reset when the difference e is inverted from plus to minus or from minus to plus. This is done to return the differential term output value Q_d to the initial state when the difference e is inverted after the operation of correction means 4 because limiting with the differential term output value Q_d has already become unnecessary.

[0025] The operation of the present embodiment based on the above-described configuration will be described below with reference to FIG. 6.

[0026] An example shown in the figure relates to the case in which the actual revolution speed E_n is brought down to the target revolution speed E_o at the time of revolution matching of a fully automatic transmission or a semiautomatic transmission in which a manual transmission is switched by mechanical operations.

[0027] First, an assumption is made that the clutch is disengaged. Then the control with correction means 4 is terminated and a typical proportional integral control is carried out till the actual revolution speed E_n approaches the target revolution speed E_o within the prescribed value Z (about 400 rpm). Thus, referring to FIG. 4, when the integral term output value Q_i is found, the functions of all the elements constituting the correction means 4 are terminated and the addition value Q_{i2} is directly outputted without being upper limit controlled or lower limit controlled and becomes the integral term output value Q_i . The final injection quantity Q is then found, as shown in FIG. 1, by using the integral term output value Q_i . Thus, conducting the usual proportional integral control makes it possible to carry out control with excellent speed response till the actual revolution speed E_n approaches the target revolution speed E_o within the prescribed value Z .

[0028] However, if such a proportional integral control is continued after the actual revolution speed E_n has approached the target revolution speed E_o within the prescribed value Z , when the actual revolution speed E_n is brought down to the target revolution speed E_o , the difference e obtained by subtracting the actual

revolution speed E_n from the target revolution speed E_o becomes negative. As a result, both the output value Q_{i1} shown in FIG. 4 and the previous value Q_{i-1} become negative and subtraction is continued in the process for computing the integral term output value Q_i till the difference becomes 0. For this reason, at the point in time at which the difference becomes 0, the fuel injection quantity can become too small causing undershoot (the actual revolution speed E_n is less than the target revolution speed E_o). In the present embodiment, in order to prevent such an overshoot, the lower limit of the addition value Q_{i2} in the process for computing the integral term output value Q_i is limited by the larger (Q_y) of 0 or the differential term output value Q_d , thereby preventing the fuel injection quantity from becoming too small.

[0029] This procedure will be explained hereinbelow with reference to FIG. 6. Before the actual revolution speed E_n approaches the target revolution speed E_o within the prescribed value Z , a value with an upper limit or lower limit which is not limited by correction means 4 is used as the integral term output value Q_i in the present embodiment (region A). Once the actual revolution speed E_n has thereafter dropped so as to become less than the prescribed value Z from the target revolution speed E_o , the lower limit of the addition value Q_{i2} in the process for computing the integral term output value Q_i is limited by a larger of 0 and the differential term output value Q_d . In the example shown in the figure, it is limited by 0 (region B). If the actual revolution speed E_n then further decreases and the differential term output value Q_d accordingly becomes more than 0, the lower limit of the addition value Q_{i2} in the process for computing the integral term output value Q_i is limited by the differential term output value Q_d rather than 0 (region C).

[0030] Once the lower limit of integral term output value Q_i has been limited by the differential term output value Q_d in the region C, the limited value thereof becomes the previous value Q_{i-1} , as shown in FIG. 4, and is successively integrated. The integral term output value Q_i thus obtained is converged to a value matching the target revolution speed E_o , as shown in FIG. 6. Then, in point D, the integral term output value Q_i becomes larger than the differential term output value Q_d . Therefore it is meaningless to limit the lower limit of the integral term output value Q_i based on the differential term output value Q_d . Thus, in the present control, when the integral term output value Q_i prior to limiting is less than the differential

term output value Q_d , the lower limit of the integral term output value is limited to the differential term output value Q_d or 0, thereby preventing the excess decrease in the injection quantity. Therefore, when the integral term output value Q_i becomes larger than the differential term output value Q_d , as in point D and thereafter, the control is not required. Therefore, in point D and thereafter, the differential term output value Q_d may be reset to 0. In the example shown in the figure, the reset to 0 is made in point E (a point in which the difference e is inverted from negative to positive).

[0031] As described hereinabove, in the present embodiment, undershoot caused by the excess decrease in the quantity of injected fuel is suppressed by changing the integral term output value Q_i between the regions A, B, C with correction means 4, as shown in FIG. 6. Saying the opposite, when the integral term output value Q_i is not corrected with correction means 4, the integral term output values Q_i are added up (negative addition) according to the difference e (negative value) and decrease successively. As a result, the quantity of injected fuel becomes too small with respect to the target revolution speed E_o and undershoot occurs.

[0032] FIG. 7 illustrates the case in which the actual revolution speed E_n is increased to the target revolution speed E_o . FIG. 7a shows the fluctuations of actual revolution speed E_n in the case in which the upper limit of the integral term output value Q_i is not limited based on the differential term output value Q_d , and FIG. 7b shows the fluctuations of actual revolution speed E_n in the case (present embodiment) in which the upper limit of the integral term output value Q_i was limited based on the differential term output value Q_d with the correction means 4 shown in FIG. 4 (both cases are simulated). Comparison of the two cases shows that in the present embodiment overshoot can be suppressed for the same reasons for which the above-described undershoot could be suppressed.

[0033] In the present embodiment, as shown in FIG. 2 and FIG. 5, the differential term output value Q_d was computed based on the difference e between the target revolution speed E_o and the actual revolution speed E_n . However, when the target revolution speed E_o does not change dynamically (for example, in the case of idle engine revolution speed control), because the differential value of difference e and the differential value of actual revolution speed E_n become identical, the

differential term output value Q_d may be computed by using only the differential value of the actual revolution speed E_n .

[0034] As described hereinabove, with the fuel injection quantity control device in accordance with the present invention, when the actual revolution speed of the engine is controlled to the target revolution speed, overshoot and undershoot can be suppressed.